

Please add the following new claims:

- 15 (New) A device for a motor vehicle, comprising:  
at least one laser sensor configured to determine at least one of a position and a distance of an object in a scanning area, the laser sensor including:  
a device configured to sweep at least one laser beam emitted by the laser sensor in the scanning area; and  
a power supply configured to vary a power of the laser beam as a function of a beam direction.
16. (New) The device according to claim 15, wherein the power supply is configured to supply variable power to the laser sensor, the power supply being further configured to supply power to the laser sensor as a function of the laser beam direction.
17. (New) The device according to claim 16, wherein the scanning area is subdivided into segments, each segment having a different detection relevance, and wherein the power supply is configured to supply more power to a first segment having a higher detection relevance and to supply less power to a second segment having a lesser detection relevance.
18. (New) The device according to claim 15, wherein a characteristic curve of the laser beam power is continuously variable.
19. (New) The device according to claim 15, wherein at least one of a maximum power of the laser sensor and a power characteristic across the scanning area is a function of a motor vehicle speed.
20. (New) The device according to claim 15, wherein the device configured to sweep the at least one laser beam is further configured to sweep the at least one laser beam to traverse the scanning area at different scanning speeds.
21. (New) The device according to claim 15, wherein at least one of a maximum power of the at least one laser sensor and a power characteristic across the scanning area is a function of at least one of a distance of an object detected by

the laser sensor, a direction of an object detected by the laser sensor and a type of an object detected by the laser sensor.

22. (New) A method for operating a laser sensor of a motor vehicle to ascertain at least one of a position and a distance of an object in a scanning area, comprising the steps of:

sweeping at least one laser beam in the scanning area; and  
varying a power of the at least one laser beam as a function of a beam direction.

23. (New) The method according to claim 22, further comprising the steps of:  
subdividing the scanning area into segments, each segment having a different detection relevance; and

emitting the at least one laser beam at a higher beam power in a first segment having a higher detection relevance and at a lower beam power in a second segment having a lesser detection relevance.

24. (New) The method according to claim 23, further comprising the step of emitting the at least one laser beam at a maximum beam power in a direction of travel of the motor vehicle.

25. (New) The method according to claim 22, further comprising the step of continuously varying a beam power characteristic of the at least one laser beam.

26. (New) The method according to claim 22, further comprising the step of selecting at least one of a maximum beam power of the at least one laser beam and a power characteristic of the at least one laser beam across the scanning area as a function of a vehicle speed.

27. (New) The method according to claim 22, further comprising the step of traversing the scanning area of the laser sensor at different scanning speeds.

28. (New) The method according to claim 22, further comprising the step of selecting at least one of a maximum beam power of the at least one laser sensor